## Using houghlines

Here we learn how to use opency's hough lines

```
(ns opencv3.hough
  (:require
    [opencv3.utils :as u]
    [opencv3.colors.rgb :as color]
    [opencv3.core :refer :all]))
nil
```

Let's load the target image, and convert it to gray with a bit of blur, so that canny can work on it.

```
(def parking (-> "resources/images/lines/parking.png" imread
(u/resize-by 0.3)))
(u/mat-view parking)
```

Edges detection is done using canny.

```
(def edges (-> gray clone (canny! 50 150 )))
(u/mat-view edges)
```

Let's setup the parameters for the hough lines detection.

```
(def rho 1); distance resolution in pixels of the Hough grid
```

```
(def theta (/ Math/PI 180)); # angular resolution in radians of the
Hough grid
(def min-intersections 15); # minimum number of votes (intersections in
Hough grid cell)
(def min-line-length 50); # minimum number of pixels making up a line
(def max-line-gap 20); # maximum gap in pixels between connectable
line segments

(def lines (new-mat))
(hough-lines-p edges lines rho theta min-intersections min-line-length
max-line-gap)
```

Now that we have the lines, let's draw them on a clone of the original picture.

```
(def result (clone parking))
(dotimes [ i (.rows lines)]
(let [ val (.get lines i 0)]
   (line result
        (new-point (nth val 0) (nth val 1))
        (new-point (nth val 2) (nth val 3))
        color/teal
        2)))
nil
```

Finally, output all the intermediate images used in this guide. Let's not forget that honcat and vocncat need all the pictures to be in the same format, in our case, the same number of channels. We convert back *gray* and *edges* with the proper number of channels.

